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as set forth below to place the application in condition for allowance.

IN THE CLAIMS:

Please cancel claims 12-18 without prejudice.

Please amend claims 1 and 19 as follows:

1. (Currently Amended) A method of determining a relative position and orientation between a base camera and a non-base camera, comprising:

measuring a path of an a moving object with the base camera in a base coordinate frame:

measuring the object path with the non-base camera in a non-base coordinate frame:

calculating transformation parameters based on the object path; applying the transformation parameters to the object path measured by the non-base camera such that the object path measured by the non-base camera is expressed in the base coordinate frame.

- 2. (Previously Presented) The method of claim 1, wherein the object path is a path of a person moving around a scene.
- 3. (Original) The method of claim 1, wherein calculating transformation parameters comprises performing matching of data measured by the base and non-base cameras.
- 4. (Original) The method of claim 3, wherein data matching is used to solve a set of transformation equations.
- 5. (Original) The method of claim 4, wherein data matching comprises selecting a time value and matching points of the object path as measured by the base camera at the time value with points of the object path as measured by the non-base

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camera at the time value.

- 6. (Original) The method of claim 5, wherein interpolation is used to generate a data point at the time value if no data point was measured at the time value.
- 7. (Original) The method of claim 3, further comprising using an error minimization technique to determine transformation parameters with the least amount of error.
- 8. (Original) The method of claim 7, wherein the error minimization technique is a least squares solution.
- 9. (Original) The method of claim 7, wherein the error minimization technique is a least median of squares solution.
- 10. (Original) The method of claim 3, further comprising applying a time offset to data from at least one of the base and non-base cameras to correct for unsynchronized data between the base and non-base cameras.
- 11. (Original) The method of claim 10, wherein a set of time offset value and corresponding transformation parameters are calculated and an error minimization technique is used to determine the time offset value with the least amount of error.
 - 12. (Canceled)
 - 13. (Canceled)
 - 14. (Canceled)
 - 15. (Canceled)

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16. (Canceled)

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- 17. (Canceled)
- 18. (Canceled)
- 19. (Currently Amended) A method of calibrating a first and a second range camera, comprising:

measuring a path of an <u>a moving</u> object with the first range camera to generate a first observed object path;

measuring the object path with the second range camera to generate a second observed object path; and

calculating a transformation parameter that causes the first observed object path to approximately overlap with the second observed object path so as to determine a relative pose between the first and second range cameras.

- 20. (Original) The method of claim 19, wherein the transformation parameter is calculated using a time offset value.
 - 21. (Canceled)
 - 22. (Canceled)
 - 23. (Canceled)
 - 24. (Canceled)
 - 25. (Canceled)